

Specification

Robot type			MZ25-01	
Structure			Articulated robot	
Degree of Freedom			6	
Maximum motion range	Arm	J1	Swivel	$\pm 2.97\text{rad}$ ($\pm 170^\circ$)
		J2	Forward/Backward	+1.83 to -2.62rad (+105 to -150°)
		J3	Upward/Downward	+5.04 to -2.81rad (+289 to -161°)
	Wrist	J4	Rotation2	$\pm 3.32\text{rad}$ ($\pm 190^\circ$)
		J5	Bend	$\pm 2.53\text{rad}$ ($\pm 145^\circ$)
		J6	Rotation1	$\pm 6.28\text{rad}$ ($\pm 360^\circ$)
Maximum Velocity*1	Arm	J1	Swivel	3.67rad/s (210°/s)
		J2	Forward/Backward	3.23rad/s (185°/s)
		J3	Upward/Downward	4.71rad/s (270°/s)
	Wrist	J4	Rotation2	7.33rad/s (420°/s)
		J5	Bend	7.33rad/s (420°/s)
		J6	Rotation1	11.73rad/s (672°/s)
Maximum Payload		Wrist	25kg	
Maximum static load torque		J4	Rotation2	52N·m
		J5	Bend	52N·m

	J 6	Rotation1	32N·m
Maximum moment of inertia* ²	J 4	Rotation2	2.4kg·m ²
	J 5	Bend	2.4kg·m ²
	J 6	Rotation1	1.3kg·m ²
Maximum Reach			1,882mm
Position repeatability* ³			±0.05mm
Air tubes			IN : Ø6×1, OUT : Ø10×1
Application cables			24 wires (Including wires for optional valves)
Mounting Condition			Floor / Inverted / Angle
Ambient Temperature			0 to 45C°* ⁴
Ambient Humidity			20 to 85%RH (No dew or frost allowed)
Protection class			IP 67 equivalent (dust-proof, moisture-resistant)
Robot weight			250kg

1[rad]=180/π[°] 1[N·m]=1/9.8[kgf·m]

*1: The maximum velocity in the chart is the maximum value.

It will change depending on the operation program and the wrist load condition.

*2: Depends on wrist load condition

*3: JIS B 8432 conformance

*4: Using at 1000 m or lower sea level.

Ambient temperature has limitations when allowable altitude is exceeded